

Amendments to the Claims:

The following listing of claims will replace all prior versions, and listings, of claims in the application:

1. (Currently Amended) A control system for supplying a control signal to a controlled apparatus, the system comprising:
 - an error generator that produces an error signal from a feedback value relating to a measured first operating parameter of a controlled apparatus, and a required value relating to a desired first operating parameter value of the controlled apparatus;
 - a controller that receives the error signal and a gain signal, and generates a control signal based on the values thereof;
 - a gain selector; and selector;
 - a disturbance compensator that receives an input value relating to a measured second operating parameter of the controlled apparatus; apparatus and produces a compensation signal; and receives the error signal, produces a compensated error signal based on the input value and the error signal, and provides the compensated error signal to the gain selector;
 - a multiplier that receives the error signal and the compensation signal, produces a compensated error signal based on a multiplication of the compensation signal and the error signal, and provides the compensated error signal to the gain selector;
- wherein the gain selector receives the compensated error signal and provides the gain signal to the controller based on the value of the compensated error signal.
2. (Previously Presented) The control system according to claim 1, wherein the control signal generated by the controller is equivalent to the error signal multiplied by the gain signal.
3. (Previously Presented) The control system according to claim 1, wherein the error signal equals the difference between the required value and the feedback value.

4. (Previously Presented) The control system according to claim 1, further comprising a filter that filters the error signal and supplies a filtered error signal to the disturbance compensator in place of the error signal.

5. (Canceled)

6. (Previously Presented) The control system according to claim 1, wherein the disturbance compensator comprises a lookup table for receiving the input value, and a multiplier for receiving a compensation value from the lookup table, and for multiplying the error signal by the compensation value to produce the compensated error signal.

7. (Currently Amended) A method for controlling a controlled apparatus having a measured first operating parameter, the method comprising:

generating an error signal from a feedback value relating to a measured first operating parameter of a controlled apparatus and a required value relating to a desired value of the first operating parameter of the controlled apparatus;

generating a compensated error signal based on a multiplication of an input value value, relating to a measured second operating parameter of the controlled apparatus, apparatus and the with the error signal;

selecting a gain signal based on the compensated error signal; and

generating a control signal based on the error signal and the gain signal.

8. (Previously Presented) The method according to claim 7, wherein the control signal is equivalent to the error signal multiplied by the gain signal.

9. (Previously Presented) The method according to claim 7, wherein the error signal equals the difference between the required value and the feedback value.

10. (Previously Presented) The method according to claim 7, wherein the error signal is filtered and a filtered error signal is used in place of the error signal to generate the compensated error signal.

11. (Canceled)
12. (Canceled)
13. (Original) A gas turbine engine controller including a control system as claimed in claim 1.
14. (Previously Presented) A controller as claimed in claim 13, wherein the measured first operating parameter is temperature.
15. (Original) A method of controlling a gas turbine engine including a method as claimed in claim 7.
16. (Previously Presented) A method as claimed in claim 15, wherein the measured first operating parameter is temperature.
17. (Previously Presented) A controller as claimed in claim 13, wherein the measured second operating parameter is acceleration.
18. (Previously Presented) A method as claimed in claim 15, wherein the measured second operating parameter is acceleration.